

ABSTRACT OF THE DISCLOSURE

A dual spherical ball clamp is employed to allow for pivotal adjustment of a robotic arm to support an object in a desired position. The clamp is formed by a pair of clamp halves bolted together to form a pair of sockets. Each socket receives a spherical ball of an arm. The edges of the dual spherical ball clamp are slightly inclined outwardly with respect to the lower surface of the dual spherical ball clamp to provide for additional range of motion of the arms.

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